

IN THE CLAIMS:

The text of all pending claims, (including withdrawn claims) is set forth below. Cancelled and not entered claims are indicated with claim number and status only. The claims as listed below show added text with underlining and deleted text with ~~striketrough~~. The status of each claim is indicated with one of (original), (currently amended), (cancelled), (withdrawn), (new), (previously presented), or (not entered).

1-9. (Cancelled)

10. (Previously Presented) A method of controlling a robot system including a mobile robot with a driving part to move, the method comprising:

providing a light commander to emit light and give a command corresponding to a reflecting position at which the light is reflected;

providing a memory to store the command, and command pattern formed by the reflecting which corresponds to the command;

detecting the reflecting position by the light from the light commander at a predetermined time interval;

determining a reflecting trace based on the reflecting position when a interval change between a first and second reflecting position is within a predetermined interval;

determining whether the reflecting trace is in accordance with the command pattern; and

controlling the mobile robot to operate according to the command corresponding to the command pattern when the reflecting trace is in accordance with the command pattern,

wherein a plurality of reflecting traces corresponding to a plurality of command patterns are combined and stored as a single command pattern in the memory.

11. (Original) The method according to claim 10, wherein when the reflecting trace is not in accordance with the command pattern and draws a line segment, the mobile robot is controlled to move along the line segment.

12. (Original) The method according to claim 10, wherein when the reflecting trace is not in accordance with the command pattern and draws a closed loop, the mobile robot is controlled to enter an area formed by the closed loop.

13. (Original) The method according to claim 10, wherein when the reflecting trace is not in accordance with the command pattern and points to a point, the mobile robot is controlled to move to the point.

14-15. (Cancelled)